

Amendments to the Specification:

Please replace paragraph [0004] with the following paragraph:

[0004] The disadvantage of these known wrist axes is the fact that the lines can be damaged in operation because they are exposed to severe friction from the inner walls and the transitional radii in the internal conduit of the wrist axis. Such damage to the lines with industrial robots during production leads to costly stoppages. Furthermore, a complete bundle of lines has to be replaced if there is damage to one line, resulting in substantial repair costs.

Please replace paragraph [0029] with the following paragraph:

[0029] On the side of the mounting plate ~~10~~ 12 facing the robot arm 1, a pleated bellows 14, 15, 16 is pressed onto the screw-in nipple 13. The pleated bellows 14, 15, 16 carry the lines 9, 10, 11 in an axially compliant manner and additionally seal the conduit for the lines, thereby preventing an exchange of fluid between the robot wrist axis 3 and the robot arm 1. This is advantageous because an exchange of fluid between the wrist axis 3 and the robot arm 1 would make cost-intensive cleaning necessary.

Please replace paragraph [0034] with the following paragraph:

[0034] As an alternative, it is also possible that several lines are carried jointly through a single bellows. In this instance, the lines are preferably passed through a guide plate which rigidly positions the lines in a predetermined position relative to one another. The guide plate with the individual lines is then located axially as an entity by the bellows. The bellows therefore preferably encompasses the guide plate and is preferably pressed against the peripheral ~~at~~ edge of the guide plate by an annular spring.

Please replace paragraph [0040] with the following paragraph:

[0040] FIG. 4 shows a further embodiment of a robot wrist axis 3' in accordance with the invention with three members 4', 5', 6' which can be rotated relative to each other and a conduit 8' for lines 8', where numerous lines 22 are carried in a spiral around additional line 23 disposed in the middle. The spiral winding of the lines ~~23~~ 22 allows axial compensation

in length with the movement of the individual members 4', 5', 6' of the robot wrist axis 3'.

The invention is not limited to the previously described embodiments of the invention.

Rather, a plurality of variations and derivations is possible, which similarly make use of the inventive idea and therefore fall under its protection.